Please amend the paragraph at column 4, lines 58 to 63, as follows:

-- The status transition preparation portion 140 sets the states passed through from the state at the start of the operation of the robot 1 (starting state) to the state at the end of the operation (target state) and prepares a status transition chart (FIG. 4 etc.) as an operational state model based on the set states and the operational arcs at the time of transition between states. --

Please amend the paragraph at column 8, lines 62 to 64, as follows:

-- When the value v of the uniform [unifoorm] random number is in the range of $s_k \leq v < e_k$, the operational arc A^k_{ij} corresponding to the value v of the uniform random number is selected. --

Please amend the paragraph at column 9, lines 31 to 35, as follows:

-- FIG. 9 is a view of the operational arcs determined [determtned] by the status transition preparation portion 140, path selection portion 142, arc selection portion 144, and data transmission portion 146 based on the status transition chart shown in FIG. 8. --

Please amend the paragraph at column 9, lines 41 to 46, as follows:

-- However, when the starting state S_S and the target state S_G match, the series of self operational arcs A^k_{GG} is produced. At this time, the operating data corresponding to the series of

operational arcs A^k_{GG} is not supplied to the drive portions 120a to 120d. In this case, the state is

not particularly changed and therefore useless processing can be eliminated. --

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Please amend the paragraph at column 10, lines 42 to 45, as follows:

-- Further, according to the methods and apparatus for control of a robot of the

present invention, it is possible to increase the number of matters [matter] expressable by the

operations of the robot. --

IN THE CLAIMS:

Please amend claims 3 to 5 as follows:

1   3. (Amended) A robot control method as set forth in claim 1, wherein said

2   [operational arc includes a] self operational arc shows [showing] the operation of said

3   robot when returning from one state among the plurality of states to the same one state.

1   4. (Amended) A robot control apparatus for controlling the operation of a robot

2   having a plurality of states corresponding to a predetermined operation,

3   at least one operational arc being determined between each of any two directly

4   passable states among said plurality of states showing the operation of the robot when

5   passing between said two states, comprising a weighting means for giving to each of the